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**1. A kinematic-independent dead-reckoning sensor for indoor mobile robotics**

Bonarini, A.; Matteucci, M.; Restelli, M.;  
Intelligent Robots and Systems, 2004. (IROS 2004). Proceedings. 2004  
IEEE/RSJ International Conference on  
Volume 4, 28 Sept.-2 Oct. 2004 Page(s):3750 - 3755 vol.4  
IEEE CNF

**2. Computation of shape through controlled active exploration**

Smith, C.E.; Papanikolopoulos, N.P.;  
Robotics and Automation, 1994. Proceedings., 1994 IEEE International  
Conference on  
8-13 May 1994 Page(s):2516 - 2521 vol.3  
IEEE CNF

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Figure 4 shows an **image** captured by the CCD **camera** and sent directly to a PC. ... Similarly, to operate dexterously, **robots** must sense both the grasping and ...  
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MICRO-EPSILON is an authority in providing **displacement** solutions.  
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A point in the **image** of one **camera** must be identified and located. The same point must be located in the **image** of the second **camera**. ...  
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Research centers, Faculty of Mechanical Eng., Technion

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ongoing pose of a mobile **robot** cannot be estimated using internal sensors only, and ... is the current state vector ( $u, v$  **image** coordinates) and  $v$  ...  
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**motion** attached to the bottom hull and two for horizontal **motion** located on the ... An integral part of the vision system is the RHP-320WP infrared **camera** ...

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ment of  $B$  to a new configuration describes the **motion**, which we define as.  
 $u(x, t) = \kappa(x, t) - x$  ... **camera image**. Given applied traction field  $\Phi$ , we used ...

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